

2. (Amended) Method according to claim 1, wherein calculating the position of the target is effected by reading with the sensor which comprises a non-contact sensor.

3. (Amended) Method according to claim 1, wherein calculating the position of the target is effected by reading with the sensor which comprises a contact sensor.

4. (Amended) Method according to claim 1, wherein the target comprises a groove with substantially vertical walls

5. (Amended) Method according to claim 1, wherein the target comprises an elevation with substantially vertical sides.

6. (Amended) Device for synchronizing a robot that includes a control system, a first robot part and a second robot part movably attached to the first robot part, the device comprising a target arranged on the first robot part and a sensor arranged on the second robot part, wherein the target includes several distinct detectable changes comprising step-like structural changes.

7. (Amended) Device according to claim 6, wherein the step-like structural changes comprise instantaneous level differences in the form of shoulder parts.

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